

5 a controller having a handle, the controller in electrical communication with the
6 robotic arm; and

7 wherein movement at the controller produces a proportional movement of the
8 robotic arm and surgical instrument.

Sub I 4
1 119. (New) The system of claim 118 wherein said endoscopic surgical
2 instrument is an articable endoscopic surgical instrument.

1 120. (New) The system of claim 118 wherein the articable surgical
2 instrument comprises a base, a pivot linkage, and a distal end.

1 121. (New) The system of claim 120 wherein a movement at the controller
2 results in corresponding movement of the distal end of the articable surgical instrument
3 relative to the base of the articable surgical instrument.

1 122. (New) The system of claim 121 wherein the tool attached at the distal
2 end of the articable surgical instrument is a cauterizer.

1 123. (New) A method for operating a surgical robotic system for performing
2 a surgical procedure on a patient, the method comprising:

3 1) providing a first articulate arm, a controller and an input device which
4 receives input commands, the first articulate arm in electrical communication with the
5 controller and the controller in electrical communication with the input device;

6 2) cutting at least one incision into the patient;

7 3) attaching a surgical instrument to the first articulate arm;

8 4) inserting said surgical instrument into the patient through the at least one
9 incision;

10 5) generating input commands to move said surgical instrument in
11 accordance with the procedure being performed wherein said robotic arm moves said surgical
12 instrument in accordance with the input commands; and

13 6) removing the surgical instrument from the patient.

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Cont

Sub 4
1 124. (New) The method of claim 123 wherein said surgical instrument is a
2 grasper.

1 125. (New) The method of claim 123 wherein the surgical instrument is a
2 cauterizer.

1 126. (New) The method of claim 123 wherein the surgical instrument is a
2 cutting blade.

1 127. (New) A medical robotic system, comprising:
2 a manipulator arm;
3 an endoscopic surgical instrument movably held by the arm;
4 an input device having a handle, the input device in electrical communication
5 with the arm; and
6 wherein movement at the input device produces a proportional movement of the
7 arm and surgical instrument.

1 128. (New) The system of claim 127, wherein said endoscopic surgical
2 instrument is an articable endoscopic surgical instrument.

Sub 5
1 129. (New) The system of claim 128, wherein the articable surgical
2 instrument comprises a forearm, a wrist, and an end effector.

1 130. (New) The system of claim 129, wherein a movement at the input
2 device results in corresponding movement of the end effector relative to the forearm of the
3 articable surgical instrument.

Sub 6
1 131. (New) The system of claim 130, wherein the articable surgical
2 instrument comprises an electrosurgical coagulator.

1 132. (New) A method for operating a surgical robotic system for performing
2 a surgical procedure on a patient, the method comprising:

- 3 1) providing a first articulate arm, a computer and an input device which
4 receives input commands, the first arm in communication with the computer and the computer
5 in communication with the input device;
6 2) forming at least one incision into the patient;
7 3) attaching a surgical instrument to the first arm;
8 4) inserting said surgical instrument into the patient through the at least one
9 incision; and
10 5) generating input commands to move said surgical instrument in
11 accordance with the input commands.

1 133. (New) The method of claim 132, wherein said surgical instrument is a
2 grasper.

1 134. (New) The method of claim 132, wherein the surgical instrument is an
2 electrosurgical coagulator.

1 135. (New) The method of claim 132, wherein the surgical instrument is a
2 blade.

1 136. (New) The system of claim 127, wherein the proportional movement
2 comprises pivotal movement about an incision point along a shaft coupling the surgical
3 instrument to the arm, and wherein the proportional movement of the surgical instrument as
4 shown in a display at the input device is in a direction corresponding to the movement at the
5 input device.

1 137. (New) The method of claim 132, wherein the input commands indicate
2 a direction of movement relative to a display, and further comprising moving the surgical
3 instrument in the direction of movement by pivoting a shaft of the surgical instrument about
4 the at least one incision in response to the input commands. --

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